

L Number	Hits	Search Text	DB	Time stamp
1	0	(swivel tilt) near5 (motor camera) and (gesture pointing speech multimodal) with input and target with acquisition	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 13:48
2	4	(swivel tilt) near5 (motor camera) and (gesture pointing speech multimodal) with input and target with (acquisition redirect\$4)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 13:51
3	8	(swivel tilt) near5 (motor camera) and (gesture pointing speech multimodal) and target with (acquisition redirect\$4)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 13:58
4	19	(swivel tilt) near5 (motor camera) and target with acquisition and (redirect\$4 moving aiming) with camera	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 14:03
5	0	((swivel tilt) near5 (motor camera) and target with acquisition and (redirect\$4 moving aiming) with camera) and (multimodal gesture)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 14:00
6	0	((swivel tilt) near5 (motor camera) and target with acquisition and (redirect\$4 moving aiming) with camera) and (multimodal gesture)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 14:01
7	0	((swivel tilt) near5 (motor camera) and target with acquisition and (redirect\$4 moving aiming) with camera) and (multimodal gesture)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 14:03
8	7121	(multimodal gesture)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 14:03
9	1	((multimodal gesture)) and (swivel tilt) near5 (motor camera) and target with acquisition	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 14:04
10	92	((multimodal gesture)) and (swivel tilt) near5 (motor camera)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 14:04
11	0	((multimodal gesture)) and (swivel tilt) near5 (motor camera)) and pointing with target	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 14:04
12	21	((multimodal gesture)) and (swivel tilt) near5 (motor camera)) and pointing same (location object target)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 14:05

13	22	(((multimodal gesture)) and (swivel tilt) near5 (motor camera)) and (pointing gesturing) same (location object target)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 14:05
14	0	(((multimodal gesture)) and (swivel tilt) near5 (motor camera)) and (pointing gesturing) same (location object target)) and (orienting moving redirecting directing tilting) with camera with response	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 14:07
15	13	(((multimodal gesture)) and (swivel tilt) near5 (motor camera)) and (pointing gesturing) same (location object target)) and (orienting moving redirecting directing tilting) with camera and response	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 14:12
16	3763	345/862,863,727,716;382/103,255,286,293,311,312;348/169.ccls.	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 14:13
17	2	345/862,863,727,716;382/103,255,286,293,311,312;348/169.ccls. and (redirecting orienting moving) with camera and swivel near4 camera	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2004/08/27 14:14


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... It also included responding to two surveys in 2002 that provided **input** to the ... Modern technology enables communications both into and out of the **moving** vehicle. ...

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... to a dual chan- nel liquid **swivel** (Instech, Plymouth ... an Olympus Magnafire Digital CCD **camera** (Model S99806 ... both probe placements within the **target** regions (mPFC ...

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... Augmented Reality Employing Consistent Illumination A consistent **input**/simulation/ represen- tation pipeline on the one hand, and a geometrically reconstructed ...

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... will also feed in as **input** into further work ... transmit images, and therefore the **camera** is rarely ... this shows that decision-makers could **target** user-requirements ...

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... in Europe MSA CWA 14536:2002 Functional Specification of an Open **Multimodal** Tracking & ... air heaters for space heating not exceeding a net heat **input** of 300 kW ...

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... World Wide Web, the Community Research for AT project solicited **input** from 50 ... mental retardation or mental illness and has succeeded in **moving** many individuals ...

www.atnet.org/CR4AT/PositionPapers/Is%20It%20Working-book.pdf - [Similar pages](#)

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... working days. If, in exceptional circumstances, we cannot meet this **target**, we will explain why and give you a new deadline. If ...

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... work will be extended, with additional resources being directed at **target** groups to ... in May 2000, with the theme "keeping Bracknell Business **Moving**", and has a ...

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Searching for **PHRASE** **swivel camera pointing orienting moving redirecting target**.

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[Describing Motion for Recognition - Little, Boyd \(1995\) \(Correct\) \(20 citations\)](#)

of images of a **moving** figure, taken by a static **camera**, and derive dense optical flow data for the from the motion of the centroid of the **moving points** (assuming a static background) to the integral Abstract Our goal is to describe motion of a **moving** human figure in order to recognize individuals by vision.ucsd.edu/~jeffboyd/papers/scv95.ps.gz

[Segment-Based Structure from an Imprecisely Located Moving... - Mart'inez Zhang \(1995\) \(Correct\) \(2 citations\)](#)

Structure from an Imprecisely Located **Moving Camera** J.M. Mart'inez Z. Zhang L. Montano was proposed in [8] although they proposed to use **points** and lines, but not an specific treatment for line stereo. The proposed method improves 3D segment **orientation** computation and reduces the number of www.cps.unizar.es/~josemari/iscv95.ps.gz

[Topological Maps for Visual Navigation - Santos-Victor, Vassallo, Schneebeli \(Correct\)](#)

visual-based indoors navigation based on a single **camera** that provides the required visual feedback and velocity, detecting obstacles, going to a **point**, etc. Although vision can provide a rich to the environment. Once the robot position and **orientation** are known, a suitable trajectory is defined ftp.ele.ufes.br/pub/publications/papers/Hans/99-icvs.ps.gz

[A high Precision Laser Alignment Monitoring System for HERMES .. - Shibata Sakemi \(Correct\)](#)

of a He-Ne laser, Fresnel zone plates, CCD **cameras**, and electronics to read out the image. It length so that the laser beam is focussed at a xed **point** where the CCD **camera** is located. Five types of a He-Ne laser light source, Fresnel zone plates, **moving** mechanisms for the Fresnel zone plates, CCD dxhra1.desy.de/notes/pub/98-LIB/sakemi.98.007.ps.gz

[Large Accurate Internal Camera Calibration using Rotation with.. - Stein \(Correct\)](#)

Large Accurate Internal **Camera** Calibration using Rotation with Analysis of ftp.ai.mit.edu/pub/users/gideon/papers/iccv95-error-analysis.ps.Z

[A Modular Low-Cost Active Vision Head - Fellenz, Hartmann \(Correct\)](#)

a separate pan-tilt unit and two integrated CCD-**cameras** mounted on a vergence platform allows the agents can be used at the next higher level. **Pointers** show the flow of information between modules at and feedback Sensoric input kinematic **oriented** repr. RS-232 protocol position, pan, tilt www.mth.kcl.ac.uk/~fellenz/WWW/stereo_big.ps.gz

[Planning Referential Acts for Animated Presentation Agents - André, Rist \(Correct\)](#)

attention to graphical object representations by **pointing** with body parts, and additional devices such as of the **pointing** gesture, the system considers the **orientation** of the vector from the Persona to the **target** alternatives via linguistic means (cf. 7) When **moving** from language discourse to a multimedia ftp.dfki.uni-sb.de/pub/mm-references/andre.ps.gz

[Active Motion Detection and Object Tracking - Denzler, Paulus \(1994\) \(Correct\) \(1 citation\)](#)

parameters and by a positional change of the **camera** mounted on a robot's hand. With a combination of near the snake -the snake will collapse to one **point**, and therefore it is sufficient to do a coarse between control and vision modules. Object-**oriented** programming hides hardware details. 1. www5.informatik.uni-erlangen.de/TeX/Literatur/ps-dir/1994/Denzler94:AMD.ps.gz

[Multiple Vehicle Detection and Tracking in Hard Real Time - Betke, Haritaoglu, Davis \(1996\) \(Correct\) \(11 citations\)](#)

and tracking objects in images taken by a **moving camera** (or a fixed **camera** carried by a **moving** car) is the potential object marked by the four corner **points** in the image. If the correlation yields a high from sequences of gray-scale images taken from a **moving** car in hard real time. Recognition is www.cs.bc.edu/~betke/research-group/UMD-tech-report-834.ps.gz

[Fixation simplifies 3D motion estimation - Daniilidis \(1997\) \(Correct\) \(1 citation\)](#)

ference copy of the fixational rotation of the **camera**. Performance of the algorithm is tested on real the gaze direction towards the same environmental **point** through time. It was proven in the past that

P. Bouthemy, and F. Chaumette. Active **camera self-orientation** using dynamic image parameters. In Proc. www.cis.upenn.edu/~kostas/.fixation.ps.gz

Optimal Manipulation Strategies For Orienting Planar.. - Chen, Hung, Ierardi (1994) (Correct)
of the part remains: the actual location of the **point** of contact of the part along the face of the
usc.edu/pub/csinfo/tech-reports/papers/94-597.ps.Z

Techniques for Fisheye Lens Calibration using a Minimal - Number Of Measurements (Correct)
the fisheye lens and CCD **camera** were mounted on a **swivel**, which could report the angle of its **swivel**. The
is able to see half of the world. It can give a **camera** a complete view of 180 along the horizon and 180
of 180 along the horizon and 180 vertically when **pointed** forward. However, this supreme view of the world
www.mundhenk.com/research/fisheye_man.pdf

Jack Software Feature Improvements Quarterly Report - Norman Badler Pei-Hwa (Correct)
and shoulder position the elbow is still free to **swivel** about an axis from the shoulder to the wrist.
joint at the elbow. Since a goal position and **orientation** for the hand specifies six constraints, the
[2] X. Zhao, D. Tolani, B. Ting. Simulating Human **Movements** Using Optimal Control, Proceedings of the
ftp.cis.upenn.edu/pub/graphics/ho/HEL.ps.Z

The View-Graph Approach to Visual Navigation and.. - Mallot, Franz.. (1997) (Correct) (5 citations)
We use a 360 fli imaging device consisting of a **camera pointing** upwards and a conic mirror mounted on
the current "home-vector" coordinates of starting **point**) is represented, not the entire path. fli
error accumulation is a problem, the use of global **orientation** information (compasses"e.g.distant
www.cog.brown.edu/mpik-mirror/people/personal/bs/.papers/icann97.ps.gz

Mosaicing with Generalized Strips - Rousso, Peleg, Finci (1997) (Correct) (2 citations)
the objects in the scene are distant from the **camera**, and **camera** motion could be modeled as a
which is **moving** to the left. The Optical Flow **points** to the right, and vertical strips are collected.
mosaic. In the simple case of a **camera** which is **moving** horizontally, vertical sections are usually taken
www.cs.huji.ac.il/papers/IP/IUW97/general-mosaics.ps.gz

A Bayesian Computer Vision System for Modeling Human.. - Oliver, Rosario, Pentland (1999) (Correct) (38 citations)
2 System Overview Our system employs a static **camera** with wide field-of-view watching a dynamic
into 'atomic' behaviors such as, for example, a **pointing** gesture or a car turning left. However, there
are satisfied. For each agent the position, **orientation** and velocity is measured, and from this data
drew.www.media.mit.edu/~nuria/authoring/./humanBehavior/icvs99.ps.gz

A Feedback Mechanism for Query by Navigation - Berger, van der Weide (1995) (Correct) (1 citation)
In terms of the previous example, at some **point** in time a possible interest in Paris may be
with its structuring, comprises the Hyperindex. **Moving** from the Hyperbase to the Hyperindex is called
is, say, Rome. We shall call this probability the **target** probability. Consider the situation where the
ftp.cs.kun.nl/pub/SoftwEng.InfSyst/articles/FeedbackQBN.ps.Z

An Intelligent Observer - Becker Gonz'alez-Ba (1995) (Correct) (6 citations)
by a human operator. The robot carries one or more **cameras** which allow it to track objects while at the
is to remain in view of a **moving target** at each **point** in time. Since the **target** motion is not known in
up each edge. The slopes of these lines yield the **orientation** of the landmark their intersection **points**
robotics.stanford.edu/~hhg/doc/iser95/iser95.ps.gz

Geometry and Algebra of Multiple Projective Transformations - Heyden (1995) (Correct) (10 citations)
case where the images are taken by uncalibrated **cameras**, making it possible to reconstruct the object up
The minimal cases of two images of seven **points** and three images of six **points** are solved, giving
eines Objektes Zwei Perspektiven mit innerer **Orientierung**, Sitz-Ber. Akad. Wiss.Wien, math.
www.maths.lth.se/matematiklth/personal/andersp/publ/dissabs.ps

Dynamic Registration Correction in Video-Based Augmented.. - Bajura, Neumann (1995) (Correct) (17 citations)
see-through AR system uses head-mounted video **cameras** to view the real world and inserts the virtual
Registration can be made exact for one or more **points** in every combined image if a small video delay
usc.edu/pub/graphics/papers/cga.ps

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